First Hit Previous Doc Next Doc Go to Doc#

Generate Collection Print

L4: Entry 25 of 101 File: JPAB Nov 14, 1990

PUB-NO: JP402278313A
DOCUMENT-IDENTIFIER: JP 02278313 A
TITLE: AUTOMATIC CONTROLLER FOR COURSE AND DEPTH OF SUBMARINE

PUBN-DATE: November 14, 1990

INVENTOR-INFORMATION:

NAME	COUNTRY
OZAWA, YUJI	

ASSIGNEE-INFORMATION:

NAME	COUNTRY
NEC CORP	

APPL-NO: JP01100499
APPL-DATE: April 19, 1989

US-CL-CURRENT: 701/21; 701/202
INT-CL (IPC): G05D 1/10; B63G 8/24

ABSTRACT:

PURPOSE: To arbitrarily set a conversion path by providing a conversion path setting means setting the conversion path at the time of converting a position in the water, a motion characteristic storage means and a target value calculation means, and controlling a submarine in such a way that it can automatically move along the set conversion path.

CONSTITUTION: A conversion path setting position 1 arbitrarily sets the path with respect to the new position at the time of changing the position of the submarine, and outputs a conversion path signal related on depth and a course specifying the path to the target value calculation device 2. An automatic steering device 3 calculated under angle instructions with respect to a latent rubber 10, a horizontal rudder 11 and a vertical rudder 12 based on a deviation between a depth signal (h) from a depth sensor 5, a pitch angle signal θ from a pitch angle sensor 6 and a course signal ψfrom a course sensor 7, and a target depth, a target pitch angle and a target course supplied from the target value calculation device 2, and the device 3 supplies the instructions to a rudder driving device 4. It drives the latent rudder 10, the horizontal rudder 11 and the vertical rudder 12 by the rudder angle instructions from the automatic steering device 3. Thus, the submarine can be controlled along the arbitral conversion path which has been set.

Previous Doc Next Doc Go to Doc#